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<input type="checkbox"/>	L33	l29 and L32	378
<input type="checkbox"/>	L32	(700/245,247,248,249,250,251,252,253,254,258,259,260,261,262,263,264 or 414/754,575,777,814,783,936 or 318/568.1 or 74/490.03 or 901/16,47).ccls.	5827
<input type="checkbox"/>	L31	part\$ and assembl\$3 and L30	18
<input type="checkbox"/>	L30	(4894788 4590578 5299288 5305427 5408409 6013997 4880992 5929584 4485453 4595334 4815006 5177563 5297238 5523663 5740328 6101455 6252544 6429812 6591160 6044308 4887222 5572103 4505049 4528632 4613943 4875172 4937759 4973215 4975856 4987527 5053976 5191639 5208763 5276777 5285525 5297023 5327057 5331413 5333242 5347616 5542028 5581166 5808887 5870303 6751526 4392766 4792228 5303333 5455497 5559695).pn.	98
<input type="checkbox"/>	L29	robot\$6 and calibrations and control\$4 and (location\$ or position\$) and coordinat\$3	4459
<input type="checkbox"/>	L28	l10 and L27	102
<input type="checkbox"/>	L27	(failure or brake down or brakedown) and mode and L26	609
<input type="checkbox"/>	L26	robot\$6 and control\$3 and assembl\$3 and configuration and image and calibration and operation and user	1442
<input type="checkbox"/>	L25	robot\$6 and control\$3 and assembl\$3 and self configuration and image and calibration and operation and user	11
<input type="checkbox"/>	L24	robot\$6 and contrtol\$3 and assembl\$3 and calibration	0
<input type="checkbox"/>	L23	robot\$6 and contrtol\$3 and assembl\$3 and image and calibration	0
<input type="checkbox"/>	L22	robot\$6 and contrtol\$3 and assembl\$3 and test and image and calibration	0
<input type="checkbox"/>	L21	robot\$6 and contrtol\$3 and assembl\$3 and teat and image and calibration	0
<input type="checkbox"/>	L20	robot\$6 and contrtol\$3 and assembl\$3 and self configuration and image and calibration	0
<input type="checkbox"/>	L19	robot\$6 and contrtol\$3 and assembl\$3 and self configuration and image and calibration and operation and user	0
<input type="checkbox"/>	L18	('5963712')!.ABPN1,NRPN,PN,TBAN,WKU.	2
<input type="checkbox"/>	L17	check\$3 and L15	1
<input type="checkbox"/>	L16	(test or diagnos\$3) and L15	0
<input type="checkbox"/>	L15	rotation direction and L14	2
<input type="checkbox"/>	L14	motor and L13	10
<input type="checkbox"/>	L13	robot\$6 and (user or operator) and L12	10
<input type="checkbox"/>	L12	(4541770 4868474 4953075 5029065 5293107 5428470 5581166 5844145 5914876 5963712 5995882 6182203).pn.	23
<input type="checkbox"/>	L11	10/250549	2
<input type="checkbox"/>	L10	L9 and calibration and wafer	382
<input type="checkbox"/>	L9	robot\$6 and (semiconductor or chip or microprocessor or memory or ram or rom or ic or integrated circuit) (processing or manufactur\$3 or fabrication) and (vision or visual or camera or	1555

	video) and transmit\$4	
<input type="checkbox"/>	L8 ('5646776' '5446584' '5331458')!.ABPN1,NRPN,PN,TBAN,WKU.	4
<input type="checkbox"/>	L7 camera and L6	11
<input type="checkbox"/>	L6 (speciment or semiconductor) and L5	133
<input type="checkbox"/>	L5 L1 or L3	404
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Key: IEEE JNL = IEEE Journal or Magazine, IEE JNL = IEE Journal or Magazine, IEEE CNF = IEEE Conference, IEE CNF = IEE Conference, IEEE STD = IEEE Standard

1. **Proceedings 1999 IEEE International Conference on Robotics and Automation (Cat. No.99CH36288C)**
Robotics and Automation, 1999. Proceedings. 1999 IEEE International Conference on
Volume 1, 10-15 May 1999
IEEE CNF
2. **Proceedings. 1998 IEEE/RSJ International Conference on Intelligent Robots and Systems. Innovations in Theory, Practice and Applications (Cat. No.98CH36190)**
Intelligent Robots and Systems, 1998. Proceedings., 1998 IEEE/RSJ International Conference on
Volume 1, 13-17 Oct. 1998
IEEE CNF
3. **Robotic motion planning and manipulation in an uncalibrated environment**
Ghosh, B.K.; Tzyh Jong Tarn; Ning Xi; Zhenyu Yu; Di Xiao;
Robotics & Automation Magazine, IEEE
Volume 5, Issue 4, Dec. 1998 Page(s):50 - 57
IEEE JNL
4. **Planning and control of self-calibrated manipulation for a robot on a mobile platform**
Di Xiao; Ghosh, B.K.; Ning Xi; Tzyh-Jong Tarn;
Robotics and Automation, 1997. Proceedings., 1997 IEEE International Conference on
Volume 2, 20-25 April 1997 Page(s):1406 - 1411 vol.2
IEEE CNF
5. **Calibration free visually controlled manipulation of parts in a robotic manufacturing workcell**
Ghosh, B.K.; Tzyh-Jong Tarn; Ning Xi; Zhenyu Yu; Di Xiao;
Robotics and Automation, 1996. Proceedings., 1996 IEEE International Conference on
Volume 4, 22-28 April 1996 Page(s):3197 - 3202 vol.4
IEEE CNF
6. **A framework for vision-guided manipulation of a moving target**
Sharma, R.; Herve, J.-Y.; Cucka, P.;
Systems, Man, and Cybernetics, 1991. 'Decision Aiding for Complex Systems, Conference Proceedings., 1991 IEEE International Conference on
13-16 Oct. 1991 Page(s):213 - 218 vol.1
IEEE CNF

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Di Xiao, Bijoy Ghosh, Ning Xi, Tzyh-Jong Tarn, "**Multi-Sensor Based Intelligent Planning and Control for Robotic Manipulators on a Mobile Platform**", Nov. ...

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wheel **mobile platform**; f) **control** subsystem, which is. distributed on several computers. The joint axes ... **dual-manipulator intelligent robot** system. And ...

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Research topics include dexterous manipulation, vision-**based** world modeling for **mobile robot** exploration, and collective **robotic intelligence**. **Control** ...

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